AMENDMENTS TO CLAIMS

1. (Currently amended) A remote controlled robotic manipulator for manipulating a moving object comprising a motion sensor for sensing motion of a region of an object to be manipulated, and a controller for locking motion of the robotic manipulator relative to the region of the object based on the sensed motion, wherein the controller further controls for which region of the object the motion sensor senses motion.

2. (Original) A manipulator as claimed in claim 1 in which the motion sensor is controllable by a human user.

3. (Currently amended) A manipulator as claimed in claim 2 in which the motion sensor is controllable by tracking ~~the~~a visual fixation point of the user.

4. (Original) A manipulator as claimed in claim 3 in which the user views a remote representation of the object.

5. (Original) A method of identifying a visual fixation point of a user observing a stereo image formed by visually superposing mono images comprising the steps of presenting one mono image to each user eye to form the stereo image and tracking the fixation point of each eye.

6. (Original) A method as claimed in claim 5 in which the three dimensional position of the visual fixation point is determined.

7. (Currently amended) An apparatus for identifying a fixation point in a stereo image comprising first and second displays for displaying mono images, a stereo image presentation module for visually super-posing the mono images to form the stereo image and an eye tracker for tracking ~~the~~a fixation point of each eye.

8. (New) A manipulator as claimed in claim 1, wherein the region is within a human undergoing surgery and wherein the object is a tissue that is the subject of the surgery.

9. (New) A manipulator as claimed in claim 1, wherein the controller determines the region of the object based on a signal from an eye tracking apparatus that tracks a visual fixation point of one or more eyes of a user.

10. (New) A manipulator as claimed in claim 9, wherein the eye tracking apparatus identifies the visual fixation point of the user who is observing a stereo image formed by visually superposing mono images, comprising the steps of presenting one mono image to each user eye to form the stereo image and tracking the fixation point of each eye.

11. (New) A manipulator as claimed in claim 10 in which a three-dimensional position of the visual fixation point is determined.

12. (New) A manipulator as claimed in claim 10, further comprising left and right LCD displays that display left and right images.

13. (New) A method as claimed in claim 5, wherein the mono images are obtained from sensors that are observing a human body as part of a surgery.

14. (New) An apparatus as recited in claim 7, wherein the eye tracker determines a three-dimensional position of the fixation point.

15. (New) An apparatus as recited in claim 7, further comprising a remote controlled robotic manipulator for manipulating a moving object, a motion sensor for sensing motion of a region of an object to be manipulated, and a controller for locking motion of the robotic manipulator relative to the region of the object based on the sensed motion, wherein the controller further controls for which region of the object the motion sensor senses motion.

16. (New) An apparatus as claimed in claim 15 in which the motion sensor is controllable by a human user.

17. (New) An apparatus as claimed in claim 16, wherein the eye tracker determines a three-dimensional position of the fixation point, and wherein the eye tracker controls the motion sensor.

18. (New) An apparatus as claimed in claim 7 in which a user views a remote representation of the object.

19. (New) An apparatus as claimed in claim 15, wherein the region is within a human undergoing surgery and wherein the object is an organ that is the subject of the surgery.

20. (New) An apparatus as claimed in claim 7, wherein each of the mono images depicts a region within a human undergoing surgery, and wherein the eye tracker tracks the fixation point of each eye of a surgeon.